IN THE CLAIMS:

The text of all pending claims, (including withdrawn claims) is set forth below. Cancelled and not entered claims are indicated with claim number and status only. The claims as listed below show added text with underlining and deleted text with ~~strikethrough~~. The status of each claim is indicated with one of (original), (currently amended), (cancelled), (withdrawn), (new), (previously presented), or (not entered).

Please AMEND the claims in accordance with the following:

1. (currently amended) A robot system comprising a robot, and at least one apparatus which is driven by a servomotor and carries out operation in cooperation with the robot, wherein the robot system further comprises:

a detection unit for detecting operator's approach to the specified apparatus including at least one apparatus which carries out operation in cooperation with the robot or operator's entry to an off-limit region set for the specified apparatus, provided for each specified apparatus; and

a controller to control the robot , the controller comprising:

a unit ~~for~~ connecting and interrupting power supply to the servomotor which drives the specified apparatus, provided for each specified apparatus~~;~~,

an emergency stop unit ~~for~~ receiving a notice of operator's approach or entry from the detection unit to bring the robot system into an emergency stopped state, wherein power supply to the robot and to each specified apparatus is interrupted~~;~~, and

a monitoring unit for each specified apparatus to monitor a connection state and an interruption state of power supply to the servomotor which drives the specified apparatus, and canceling the notice from the detection unit to the emergency stop unit, for the specified apparatus when the power supply is interrupted.

2. (original) The robot system according to claim 1, wherein the specified apparatus further includes the robot.

3. (currently amended) A control apparatus for controlling a robot and at least one apparatus, comprising:

a detection unit to detect an operator's approach to the apparatus; and

a controller to control the robot, the controller comprising:

a power unit corresponding to the apparatus, to connect and interrupt power supply to the apparatus~~;~~, and

an emergency stop unit to receive a notice of the operator's approach from the detection unit, and to interrupt power supply to the robot, and power supply to the apparatus via the corresponding power unit, based upon the received notice, wherein the notice is cancelled when the power supply is interrupted.

4. (currently amended) The control apparatus of claim 3, the controller further comprising a monitoring unit corresponding to the apparatus, to monitor a connection and an interruption of the power supply to the apparatus, wherein when the power supply to the apparatus is interrupted, the monitoring unit cancels the notice of the operator's approach received from the detection unit, thereby preventing the emergency stop unit from receiving the notice of the operator's approach.

5. (previously presented) The control apparatus of claim 3, wherein the apparatus comprises a plurality of apparatuses, wherein when an operator approaches one of the plurality of apparatuses, the power supply to all of the apparatuses and the robot is interrupted, respectively.

6. (currently amended) A control apparatus for controlling a robot and at least one apparatus, comprising:

a detection unit to detect an operator's approach to the apparatus; and

a controller to control the robot, the controller comprising:

a power unit corresponding to the apparatus, to connect and interrupt power supply to the apparatus; , and

means for receiving a notice of the operator's approach from the detection unit, for interrupting power supply to the robot, and power supply to the apparatus via the corresponding power unit, based upon the received notice, and for canceling the notice from the detection unit when the power supply is interrupted.